

Amendment
Application No. 10/758,125

Please amend the claims as follows:

1. (Currently amended) A motor control apparatus comprising:
a rotational position sensor which detects a rotational position of a rotor of a motor when a rectangular wave control of the motor is executed;
correction means for correcting an output of the rotational position sensor on the basis of a difference in a time interval from a reference time until each control time [[o]] of the motor in the rectangular wave control; and
control means for executing the rectangular wave control of the motor based on the output of the rotational position sensor which is corrected by the correction means.
2. (Original) The motor control apparatus according to claim 1, wherein the correction means corrects the output of the rotational position sensor considering a change in a voltage phase command that decides a period during which a voltage is applied to each phase of the motor when the voltage phase command is changed.
3. (Original) The motor control apparatus according to claim 1, wherein the correction means corrects the output of the rotational position sensor considering a change in a rotational speed of the rotor when the rotational speed is changed.
4. (Original) The motor control apparatus according to claim 3, wherein the correction means corrects the output of the rotational position sensor considering a change in a rotational speed of the rotor by using a time required for rotating the rotor one time in a previous control cycle and a time required for rotating the rotor one time in a present control cycle.
5. (Original) The motor control apparatus according to claim 1, wherein the correction means corrects the output of the rotational position sensor considering a change in a voltage phase command that decides a period during which a voltage is applied to each phase of the motor and a change in a rotational speed of the rotor.

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6. (Original) The motor control apparatus according to claim 5, wherein the correction means corrects the output of the rotational position sensor considering a change in a rotational speed of the rotor by using a time required for rotating the rotor one time in a previous control cycle and a time required for rotating the rotor one time in a present control cycle.

7. (Original) The motor control apparatus according to claim 1, wherein the correction means corrects the output of the rotational position sensor according to a kind of a control method for the motor.

8. (Original) A motor control method comprising the steps of:
detecting a rotational position of a rotor of a motor when a rectangular wave control of the motor is executed;
correcting an output of the rotational position on the basis of a difference between a time interval from a reference time until a control time at which the motor is controlled based on the output of the rotational position and a time interval from the reference time until a true control time at which the motor needs to be controlled in the rectangular wave control; and
executing the rectangular wave control of the motor based on the output of the rotational position which is corrected.

9. (Original) The motor control method according to claim 8, wherein the correction corrects the output of the rotational position considering a change in a voltage phase command that decides a period during which a voltage is applied to each phase of the motor when the voltage phase command is changed.

10. (Original) The motor control method according to claim 8, wherein the correction corrects the output of the rotational position considering a change in a rotational speed of the rotor when the rotational speed is changed.

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11. (Original) The motor control method according to claim 10, wherein the correction corrects the output of the rotational position considering a change in a rotational speed of the rotor by using a time required for rotating the rotor one time in a previous control cycle and a time required for rotating the rotor one time in a present control cycle.

12. (Original) The motor control method according to claim 8, wherein the correction corrects the output of the rotational position considering a change in a voltage phase command that decides a period during which a voltage is applied to each phase of the motor and a change in a rotational speed of the rotor.

13. (Original) The motor control method according to claim 12, wherein the correction corrects the output of the rotational position considering a change in a rotational speed of the rotor by using a time required for rotating the rotor one time in a previous control cycle and a time required for rotating the rotor one time in a present control cycle.

14. (Original) The motor control method according to claim 7, wherein the correction corrects the output of the rotational position sensor according to a kind of a control method for the motor.

15. (Original) A motor control apparatus comprising:
a rotational position sensor which detects a rotational position of a rotor of a motor when a rectangular wave control of the motor is executed;
a controller that corrects an output of the rotational position sensor on the basis of a difference between a time interval from a reference time until a control time at which the motor is controlled based on an output of the rotational position sensor and a time interval from the reference time until a true control time at which the motor needs to be controlled in the rectangular wave control, and executes the rectangular wave control of the motor based on the output of the rotational position sensor which is corrected.

16. (Original) A motor control apparatus comprising:

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a rotational position sensor which detects a rotational position of a rotor of a motor when a rectangular wave control of the motor is executed;

correction means for correcting an output of the rotational position sensor on the basis of a difference between a time interval from a reference time until a control time at which the motor is controlled based on the output of the rotational position sensor and a time interval from the reference time until a true control time at which the motor needs to be controlled in the rectangular wave control; and

control means for executing the rectangular wave control of the motor based on the output of the rotational position sensor which is corrected by the correction means.